

IN THE CLAIMS:

Please amend claims 1, 3, 4, 6-11 and 13 as follows.

1. (Currently Amended) A legged mobile robot having a body, and a plurality of articulated legs each connected to the body equipped with articulated legs such that it moves by driving each leg by an actuator associated therewith, comprising characterized in that:

each leg has at least a first joint installed at each leg; and
a second joint installed at each leg at a location located below the first joint in the gravitational direction;

wherein that the actuator that drives the second joint is located at least one of a position same as that of the first joint and a position above the first joint in the gravitational direction.

2. (Original) The legged mobile robot according to claim 1, wherein at least one of an output shaft of the actuator that drives the second joint and an output shaft of a transmission element to which an output of the output shaft of the actuator is transmitted, is located coaxially with an axis of the first joint, and the second joint is connected to the output shaft located coaxially with the axis of the first joint to be driven through a rod.

3. (Currently Amended) The legged mobile robot according to claim 1 ~~or 2~~, wherein the second joint has rotation axes that are arranged in at least two different directions.

4. (Currently Amended) The legged mobile robot according to claim 1 one of claims 1 to 3, wherein the second joint is driven by a plurality of actuators and is

connected to at least one of output shafts of the actuators and output shafts of transmission elements to which outputs of the output shafts of the actuators are transmitted, to be driven through a plurality of rods.

5. (Original) The legged mobile robot according to claim 4, wherein the rods are located to be spaced by prescribed distances from axes of the second joints.

6. (Currently Amended) The legged mobile robot according to claim 1~~one~~ of ~~claim 1 to 5~~, wherein the second joint is one among the joints that the legs have, that is located farthest toward a ground-contacting end.

7. (Currently Amended) A legged mobile robot having a body, and a plurality of articulated legs each connected to the body equipped with articulated legs such that it moves by driving each leg by an actuator associated therewith, comprising characterized in that:

each leg has at least a first joint installed at each leg;

a second joint installed at each leg at a location located below the first joint in the gravitational direction; and

a speed reducer to which an output of the actuator that drives the second joint is transmitted;

wherein that an input shaft of the speed reducer is located coaxially with an axis of the first joint.

8. (Currently Amended) A legged mobile robot having a body, and a plurality of articulated legs each connected to the body equipped with articulated legs such that it

moves by driving each leg by an actuator associated therewith, comprising characterized
in that:

each leg has at least a first joint installed at each leg;

a second joint installed at each leg at a location located below the first joint in the gravitational direction;

a link that connects the first joint and the second joint; and

a speed reducer to which an output of the actuator that drives the second joint is transmitted;

wherein that a base of the speed reducer is located at the link that connects the first joint and the second joint.

9. (Currently Amended) The legged mobile robot according to claim 7 or 8, wherein an output shaft of the speed reducer is located coaxially with the axis of the first joint, and the second joint is connected to the output shaft of the speed reducer to be driven through a rod.

10. (Currently Amended) The legged mobile robot according to claim 7-one-of claim 7 to 9, wherein the second joint has rotation axes that are arranged in at least two different directions.

11. (Currently Amended) The legged mobile robot according to claim 7-one-of claims 7 to 10, wherein the second joint is driven by a plurality of actuators and is connected to output shafts of the speed reducers to which outputs of the actuators are transmitted, to be driven through a plurality of rods.

12. (Previously Presented) The legged mobile robot according to claim 11, wherein the rods are located to be spaced by prescribed distances from axes of the second joints.

13. (Currently Amended) The legged mobile robot according to claim 7-one of claim 7 to 12, wherein the second joint is one among the joints that the legs have, that is located farthest toward a ground-contacting end.